8/12/2015 الثلاثاء د. عرفة محاضرة [9]

Review: State Space

System

- D.Es (T.F)
- Block diagram or Signal flow graph
- two State eqn
- phisycal Model

$$\boxed{\begin{aligned} \dot{X} &= AX + Bu \\ y &= CX + Du \end{aligned}}$$

time domain

For state-space, the System's dynamics in time-domain.

$$\left.\begin{aligned} \dot{X}(t) &= A\,X(t) + B\,\overset{I/P}{u}(t) \\ y(t) &= C\,X(t) + Du(t) \end{aligned}\right\} \text{two state equations.}$$

where: $u(t) \longrightarrow i/p$
$y(t) \longrightarrow o/p$

$\boxed{D = 0} \Leftarrow$ درجة البسط أقل من درجة المقام في ال T.F. phisycal systems

* if D has value, then it would be a scalar (1×1)

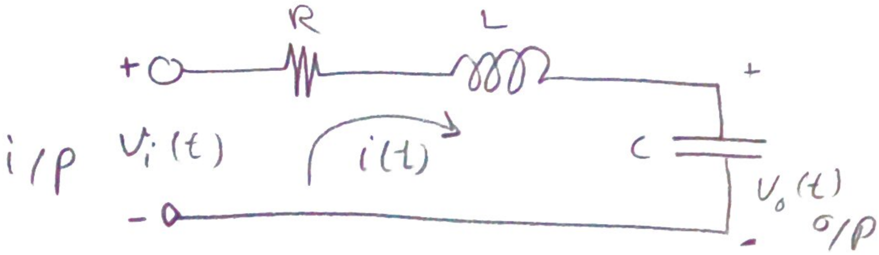
* $n \Rightarrow$ System order

- $A_{n \times n} \Longrightarrow$ System matrix
- $B_{n \times 1} \Longrightarrow$ input matrix عمود
- $C_{1 \times n} \Longrightarrow$ output matrix صف
- $X(t)_{n \times 1} \Longrightarrow$ state vector $\quad X(t) = \begin{pmatrix} x_1(t) \\ x_2(t) \\ \vdots \\ x_n(t) \end{pmatrix}$

\# $x_1, x_2, \dots x_n(t) \Rightarrow$ the states of the system

الـ States تمثل القراءات الغير بالآلة المقاسة للنظام

$\boxed{\text{States are the measured values}}$



$$i(t) = x_1(t) \qquad \dot{x} = A(t)x + Bu(t)$$
$$\underbrace{V_o(t)}_{y(t)} = x_2(t) \qquad y(t) = c\,x(t)$$

$$\begin{pmatrix} \dot{x}_1(t) \\ \dot{x}_2(t) \end{pmatrix} = \begin{pmatrix} - & - \\ - & - \end{pmatrix}_{2\times 2} \begin{pmatrix} x_1(t) \\ x_2(t) \end{pmatrix} + \begin{pmatrix} - \\ - \end{pmatrix} V_i(t)$$

$$y(t) = \begin{pmatrix} - & - \end{pmatrix}_{1\times 2} \begin{pmatrix} x_1(t) \\ x_2(t) \end{pmatrix}$$

$$* \; V_i(t) = V_R + V_L + V_o$$

محتاج أجيب التفاضلات $\dot{x}(t)$ من المعادلة

موجودين في المعادلة بنفسهما هو

$$= \underbrace{i(t)}_{x_1(t)} R + L \underbrace{\frac{di}{dt}}_{\dot{x}_1(t)} + \underbrace{V_o(t)}_{x_2(t)}$$

$$\Longrightarrow \dot{x}_1(t) = -\frac{R}{L} x_1 - \frac{1}{L} x_2 + \frac{1}{L} V_i(t)$$

$$* \; \underbrace{i(t)}_{x_1(t)} = c \underbrace{\frac{dV_o(t)}{dt}}_{\dot{x}_2(t)}$$

$$\dot{x}_2 = \frac{1}{c} x_1$$

$\Longrightarrow$ Turn over

$$\begin{pmatrix} \dot{x}_1(t) \\ \dot{x}_2(t) \end{pmatrix} = \begin{pmatrix} -\frac{R}{L} & -\frac{1}{L} \\ \frac{1}{C} & 0 \end{pmatrix} \begin{pmatrix} x_1(t) \\ x_2(t) \end{pmatrix} + \begin{pmatrix} \frac{1}{L} \\ 0 \end{pmatrix} U_i(t)$$

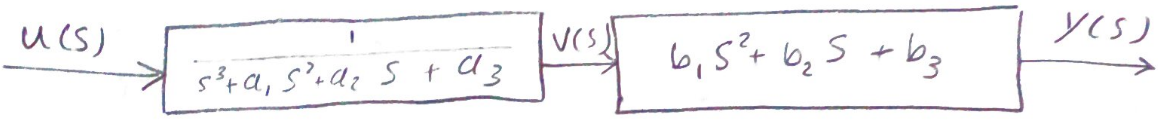
$$y(t) = \begin{pmatrix} 0 & 1 \end{pmatrix} \begin{pmatrix} x_1(t) \\ x_2(t) \end{pmatrix}$$

Canonical Forms for S.S.

$\boxed{\text{I}}$ Controllable Form

3rd order system:

$$T.F. = \frac{Y(s)}{U(s)} = \frac{b_1 s^2 + b_2 s + b_3}{s^3 + a_1 s^2 + a_2 s + a_3}$$



assume :

$V = X_1$

$\dot{V} = \dot{x}_1 = x_2$

$\ddot{V}(t) = \dot{x}_2 = x_3$

$\dddot{V}(t) = \dot{x}_3$

$\dot{x}_1 = x_2(t)$

$\dot{x}_2 = x_3(t)$

$\dot{x}_3 = \text{---}$ هاتهم بالبلاص

$= -a_3 x_1 - a_2 x_2 - a_1 x_3 + u(t)$

$$\frac{V(s)}{U(s)} = \frac{1}{s^3 + a_1 s^2 + a_2 s + a_3}$$

$$(s^3 + a_1 s^2 + a_2 s + a_3) V(s) = U(s) \quad \Downarrow L^{-1}T$$

$$\dddot{V}(t) + a_1 \ddot{V}(t) + a_2 \dot{V}(t) + a_3 V(t) = u(t)$$

$$\frac{Y(s)}{V(s)} = b_1 s^2 + b_2 s + b_3$$

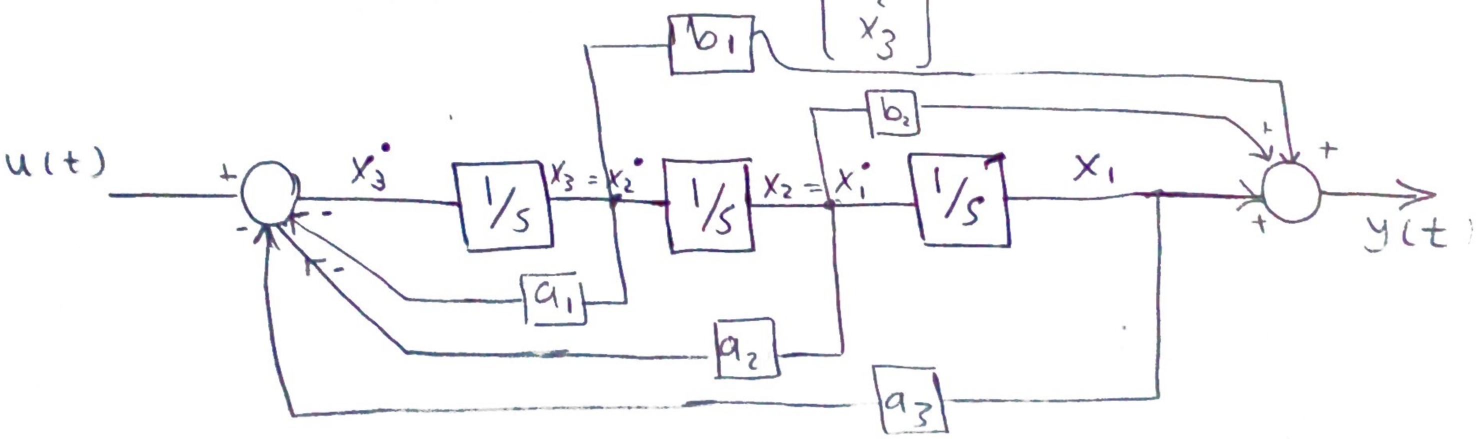
$$Y(s) = (b_1 s^2 + b_2 s + b_3) V(s)$$

$$y(t) = b_1 \underbrace{\ddot{V}(t)}_{x_3} + b_2 \underbrace{\dot{V}(t)}_{x_2} + b_3 \underbrace{V(t)}_{x_1}$$

$$y(t) = b_3 x_1 + b_2 x_2 + b_1 x_3$$

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \\ \dot{x}_3 \end{bmatrix} = \begin{bmatrix} 0 & 1 & 0 \\ 0 & 0 & 1 \\ -a_3 & -a_2 & -a_1 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix} u(t)$$

$$y(t) = \begin{bmatrix} b_3 & b_2 & b_1 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix}$$



to check controllability:
the system is controllable if you can reach any state starting from the input $u(t)$

$\Longrightarrow$ Turn Over

K1

علشان ما نتعبش كل مرة وأجيب ال Controllable form مباشرة

$$T.F. = \frac{b_1 S^2 + b_2 S + b_3}{(1) S^3 + a_1 S^2 + a_2 S + a_3}$$

(1) معاملها بـ

* عوض مباشرة في الصورة المستنتجة في الصفحة السابقة

* for 4th order System

$$T.F. = \frac{b_1 S^3 + b_2 S^2 + b_3 S + b_4}{S^4 + a_1 S^3 + a_2 S^2 + a_3 S + a_4}$$

$$\begin{pmatrix} \dot{x}_1 \\ \dot{x}_2 \\ \dot{x}_3 \\ \dot{x}_4 \end{pmatrix} = \begin{pmatrix} 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \\ -a_4 & -a_3 & -a_2 & -a_1 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \\ x_3 \\ x_4 \end{pmatrix} + \begin{pmatrix} 0 \\ 0 \\ 0 \\ 1 \end{pmatrix} u(t)$$

معاملات المقام معكوسة بإشارة سالبة

$$y(t) = \begin{pmatrix} b_4 & b_3 & b_2 & b_1 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \\ x_3 \\ x_4 \end{pmatrix}$$

معاملات البسط معكوسة

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[2] observable form:

$A_o = A_c^T$ (o → observable, c → controllable)

$B_o = C_c^T$

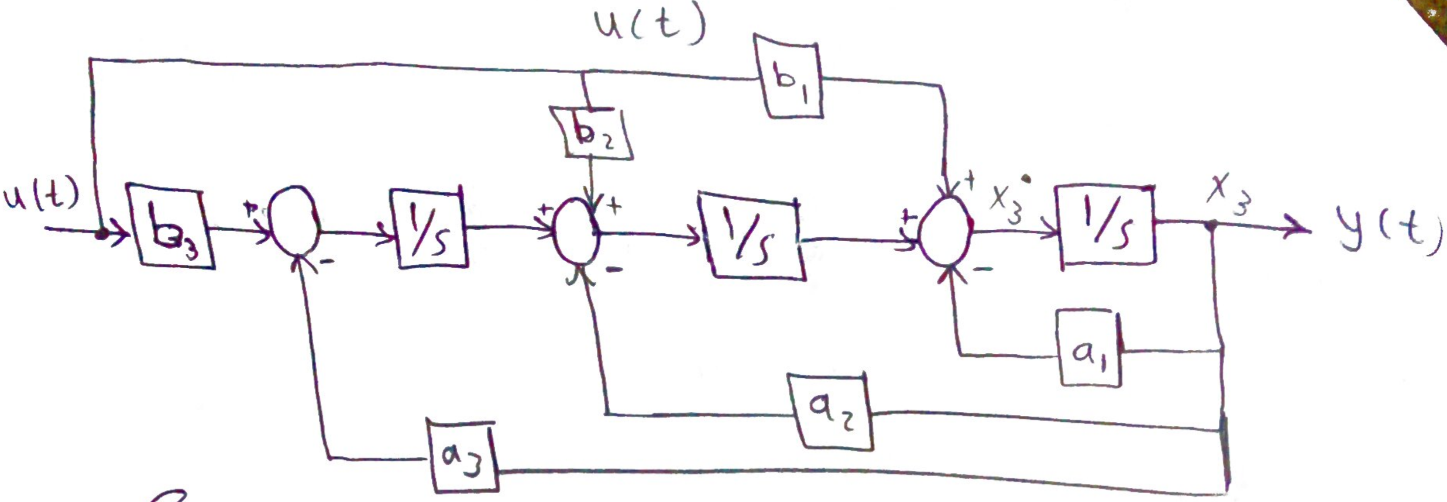
$C_o = B_c^T$

3rd order System

$$T.F. = \frac{b_1 S^2 + b_2 S + b_3}{S^3 + a_1 S^2 + a_2 S + a_3}$$

$$\underbrace{\left[\dot{X}(t) \right]}_{\dot{x}_1,\ \dot{x}_2,\ \dot{x}_3} = \begin{bmatrix} 0 & 0 & -a_3 \\ 1 & 0 & -a_2 \\ 0 & 1 & -a_1 \end{bmatrix} \left[X(t) \right] + \begin{bmatrix} b_3 \\ b_2 \\ b_1 \end{bmatrix} u(t)$$

$$y(t) = \begin{bmatrix} 0 & 0 & 1 \end{bmatrix} \underbrace{\left[X(t) \right]}_{x_1,\ x_2,\ x_3}$$



* for 4th order system

$$T.F. = \frac{b_1 s^3 + b_2 s^2 + b_3 s + b_4}{s^4 + a_1 s^3 + a_2 s^2 + a_3 s + a_4}$$

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \\ \dot{x}_3 \\ \dot{x}_4 \end{bmatrix} = \begin{bmatrix} 0 & 0 & 0 & -a_4 \\ 1 & 0 & 0 & -a_3 \\ 0 & 1 & 0 & -a_2 \\ 0 & 0 & 1 & -a_1 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \\ x_4 \end{bmatrix} + \begin{bmatrix} b_1 \\ b_2 \\ b_3 \\ b_4 \end{bmatrix} u(t)$$

$$y(t) = \begin{bmatrix} 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \\ x_4 \end{bmatrix}$$

Ex: $T.F. = \dfrac{s^2 + 6s + 8}{(s+1)(s+3)(s+5)}$

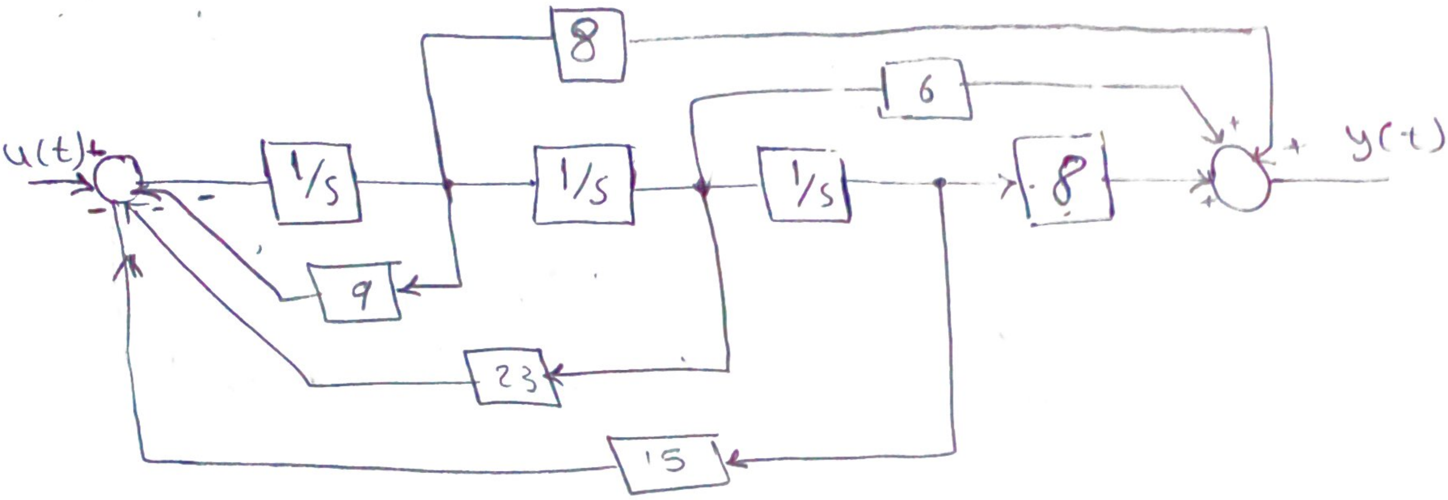
- Find state-space model in controllable and observable forms
- Draw the state diagram for each case.

$$T.F. = \frac{S^2 + 6S + 8}{S^3 + 9S^2 + 23S + 15}$$

$\boxed{1}$ Controllable Form:

$$[\dot{X}(t)] = \begin{bmatrix} 0 & 1 & 0 \\ 0 & 0 & 1 \\ -15 & -23 & -9 \end{bmatrix} [X(t)] + \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix} u(t)$$

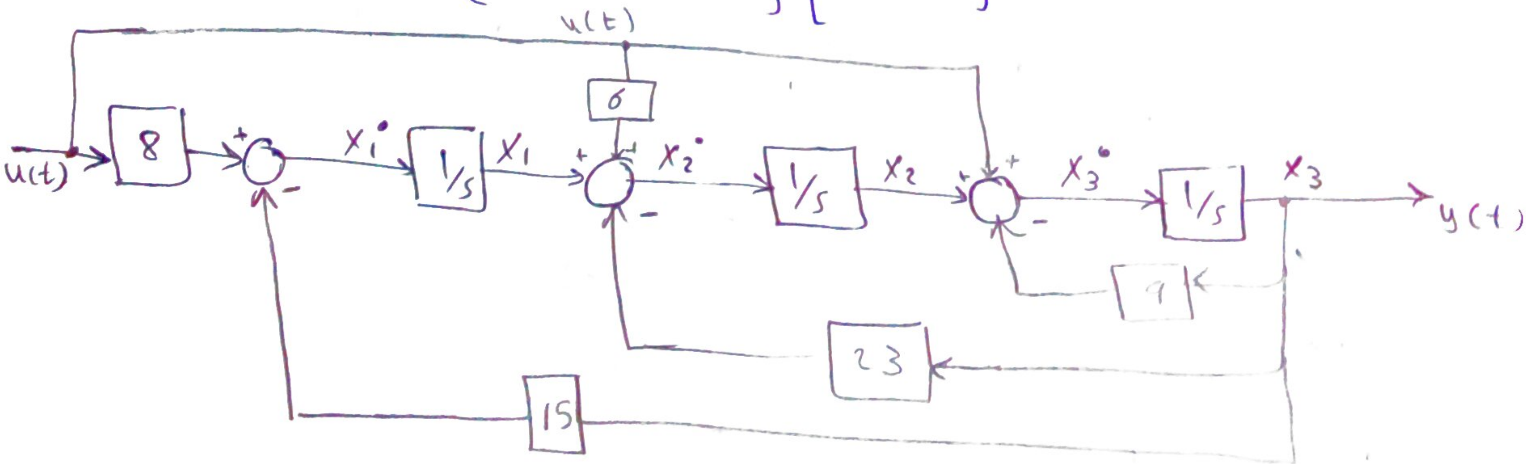
$$y(t) = \begin{bmatrix} 8 & 6 & 1 \end{bmatrix} [X(t)]$$



$\boxed{2}$ observable form:

$$[\dot{X}(t)] = \begin{bmatrix} 0 & 0 & -15 \\ 1 & 0 & -23 \\ 0 & 1 & -9 \end{bmatrix} [X(t)] + \begin{bmatrix} 8 \\ 6 \\ 1 \end{bmatrix} u(t)$$

$$y(t) = \begin{bmatrix} 0 & 0 & 1 \end{bmatrix} [X(t)]$$



3 Diagonal Form

for 3rd order system

$$T.F. = \frac{b_1 s^2 + b_2 s + b_3}{s^3 + a_1 s^2 + a_2 s + a_3} \Downarrow$$

$$= \frac{b_1 s^2 + b_2 s + b_3}{(s+P_1)(s+P_2)(s+P_3)} \Downarrow \text{P.F.}$$

$$T.F. = \frac{Y(s)}{U(s)} = \frac{A_1}{s+P_1} + \frac{A_2}{s+P_2} + \frac{A_3}{s+P_3}$$

$$Y(s) = \underbrace{\frac{U(s)}{(s+P_1)}}_{X_1(s)} A_1 + \underbrace{\frac{U(s)}{(s+P_2)}}_{X_2(s)} A_2 + \underbrace{\frac{U(s)}{(s+P_3)}}_{X_3(s)} A_3$$

$$X_1(s) = \frac{U(s)}{s+P_1}$$

$$U(s) = (s+P)\, X_1(s) \quad \Big\downarrow L^{-1}T$$

$$u(t) = \dot{X}_1(t) + P_1 X_1(t) \Longrightarrow$$

$$\dot{X}_1 = -P_1 X_1 + u(t)$$
$$\dot{X}_2 = -P_2 X_2 + u(t)$$
$$\dot{X}_3 = -P_3 X_3 + u(t)$$

$$[\dot{X}(t)] = \begin{bmatrix} -P_1 & 0 & 0 \\ 0 & -P_2 & 0 \\ 0 & 0 & -P_3 \end{bmatrix} [X(t)] + \begin{bmatrix} 1 \\ 1 \\ 1 \end{bmatrix} u(t)$$

$$Y(s) = A_1 X_1(s) + A_2 X_2(s) + A_3 X_3(s)$$

$$y(t) = A_1 X_1(t) + A_2 X_2(t) + A_3 X_3(t)$$

$$y(t) = [A_1 \quad A_2 \quad A_3]\,[X(t)]$$

assuming you got repeated poles

Poles $\longrightarrow -P_1, -P_1, -P_2$

$$T.F. = \frac{b_1 s^2 + b_2 s + b_3}{(s+P_1)^2 (s+P_2)}$$

$$Y(s) = \frac{U(s) A_1}{(s+P_1)^2} + \frac{U(s) A_2}{(s+P_1)} + \frac{U(s) A_3}{(s+P_2)}$$

$$X_1(s) = \frac{U(s)}{(s+P_1)^2} = \underbrace{\frac{U(s)}{(s+P_1)}}_{X_2} \frac{1}{(s+P_1)}$$

$$X_1(s) = \frac{X_2(s)}{(s+P_1)} \Longrightarrow \dot{X}_1 = -P_1 X_1 + X_2$$

$$X_2(s) = \frac{U(s)}{(s+P_1)} \Rightarrow \dot{X}_2 = -P_1 X_2 + u(t)$$

$$\dot{X}_3 = -P_2 X_3 + u(t)$$

$$[\dot{x}(t)] = \begin{bmatrix} -P_1 & 1 & 0 \\ 0 & -P_1 & 0 \\ 0 & 0 & -P_2 \end{bmatrix} [X(t)] + \begin{bmatrix} 0 \\ 1 \\ 1 \end{bmatrix} u(t)$$

$$y(t) = \begin{bmatrix} A_1 & A_2 & A_3 \end{bmatrix} [X(t)]$$

For

$$T.F. = \frac{b_1 s^2 + b_2 s + b_3 s}{(s+P_1)^3}$$

$$[\dot{x}(t)] = \begin{bmatrix} -P_1 & 1 & 0 \\ 0 & -P_1 & 1 \\ 0 & 0 & -P_1 \end{bmatrix} [X(t)] + \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix} u(t)$$

$$y(t) = \begin{bmatrix} A_1 & A_2 & A_3 \end{bmatrix} [X(t)]$$

Ex: $TF = \dfrac{s^2 + 6s + 8}{(s+1)(s+3)(s+5)}$

- Find the state space in diagonal form
- Draw the state diagram

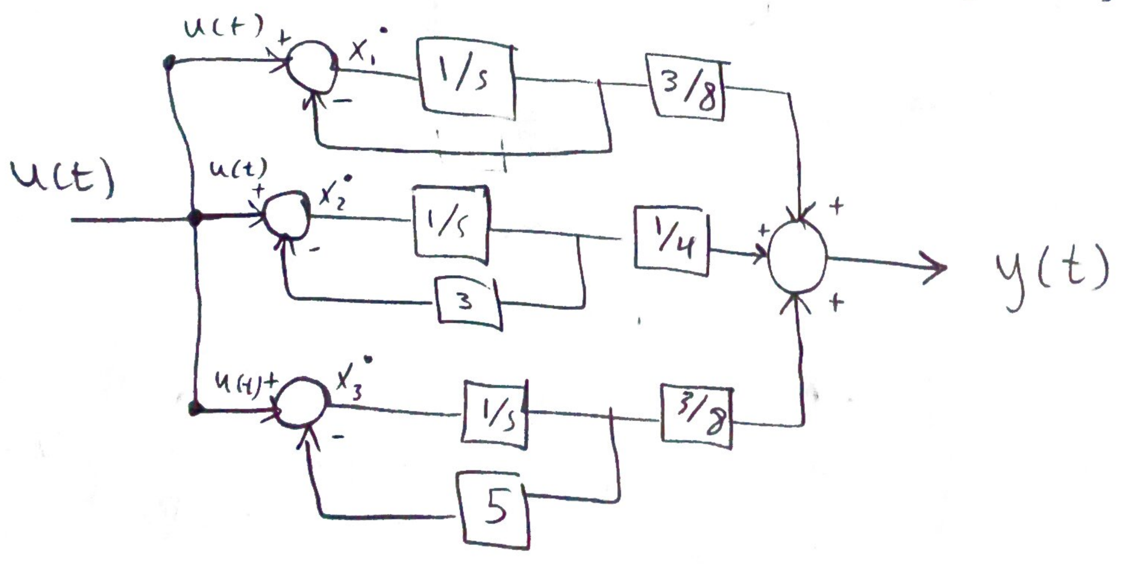
$$T.F. = \frac{s^2 + 6s + 8}{(s+1)(s+3)(s+5)}$$

$$= \frac{A_1}{(s+1)} + \frac{A_2}{(s+3)} + \frac{A_3}{(s+5)}$$

$A_1 = \dfrac{1-6+8}{(2)(4)} = \dfrac{3}{8}$; $A_2 = \dfrac{9-18+8}{(-2)(2)} = \dfrac{-1}{-4} = \dfrac{1}{4}$; $A_3 = \dfrac{25-30+8}{(-4)(-2)} = \dfrac{3}{8}$

$$[\dot{x}(t)] = \begin{bmatrix} -1 & 0 & 0 \\ 0 & -3 & 0 \\ 0 & 0 & -5 \end{bmatrix} [x(t)] + \begin{bmatrix} 1 \\ 1 \\ 1 \end{bmatrix} u(t)$$

$$y(t) = \begin{bmatrix} 3/8 & 1/4 & 3/8 \end{bmatrix} [x(t)]$$



Ex: $T.F. = \dfrac{2S^2+6S+5}{(S+1)^2(S+2)}$ $\Downarrow$ P.F.

$$T.F. = \frac{A_1}{(S+1)^2} + \frac{A_2}{(S+1)} + \frac{A_3}{(S+2)}$$

$A_1 = \dfrac{2-6+5}{(-1+2)} = 1$; $A_3 = \dfrac{8-12+5}{1} = 1$;

for A_2 put $s=0$

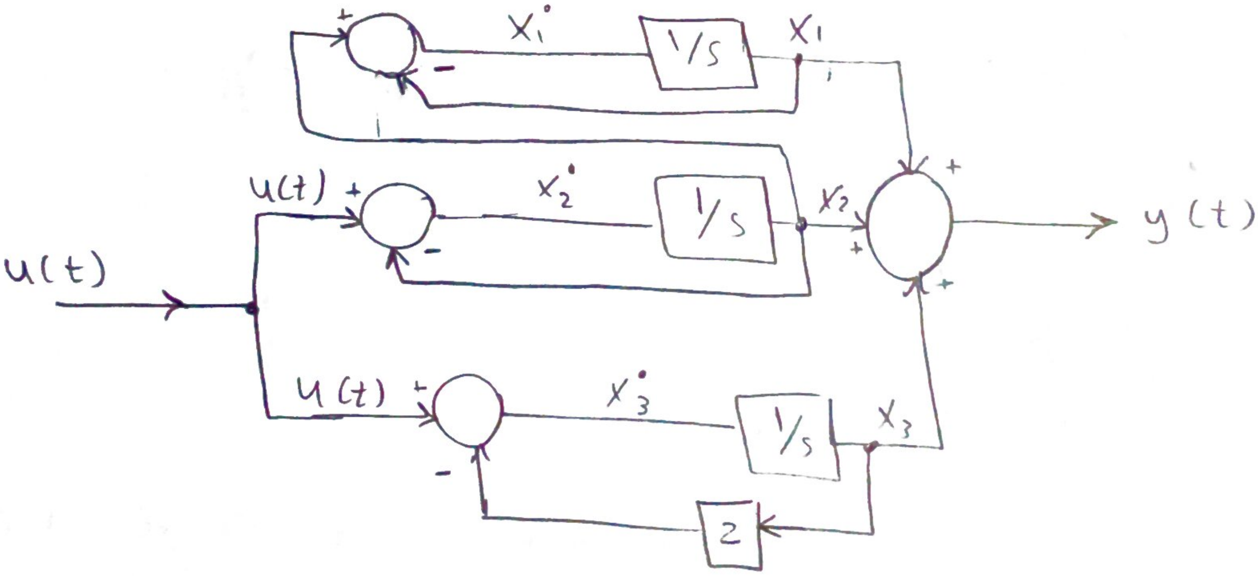
$\frac{5}{2} = A_1 + A_2 + A_3/2$

$= 1 + A_2 + 1/2$

$A_2 = 1$

$$\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \\ \dot{x}_3 \end{bmatrix} = \begin{bmatrix} -1 & 1 & 0 \\ 0 & -1 & 0 \\ 0 & 0 & -2 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} + \begin{bmatrix} 0 \\ 1 \\ 1 \end{bmatrix} u(t)$$

$$y(t) = \begin{bmatrix} 1 & 1 & 1 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix}$$



⟹ Turn Over

* State Space Analysis

given the two state equations

$$\dot{x} = Ax + Bu$$
$$y = Cx$$

1) T.F.

$$S\,X(S) = A\,X(S) + B\,u(S) \longrightarrow (1)$$
$$Y(S) = C\,X(S) \longrightarrow (2)$$

two state eqns in S-domain

$$S\,X(S) - A\,X(S) = B\,u(S)$$
$$(SI - A)\,X(S) = B\,u(S)$$
$$\Longrightarrow X(S) = (SI-A)^{-1} B\,u(S) \quad (3)$$

where $I_{n \times n}$ is identity matrix

$$Y(S) = C(SI-A)^{-1} B\,u(S) \quad (4)$$

$$T.F. = \frac{Y(S)}{U(S)} = C(SI-A)^{-1} B$$

2) Ch. eq:

$$|SI - A| = 0$$

The roots of ch. eqn = Poles = eigen values

3) The system response to i/p u(t)

o/p in time domain

if $X(0) \neq 0$

$\Longrightarrow$ Turn over

if $X(0) \neq 0$

$$\dot{X}(t) = A x(t) + B u(t) \xrightarrow{LT} S X(s) - X(0) = A X(s) + B u(s)$$

$$S X(S) - A X(S) = X(0) + B u(S)$$

$$(S I - A) X(S) = X(0) + B u(S)$$

$$X(S) = (SI - A)^{-1} X(0) + (SI - A)^{-1} B u(S)$$

Let $\phi(S) = (SI - A)^{-1} \Rightarrow$ Transition Matrix

$$X(S) = \phi(S) X(0) + \phi(S) B u(S)$$

$$y(t) = C x(t)$$

$$y(S) = C X(S)$$

$$= C [\phi(S) X(0) + \phi(S) B u(S)]$$

$$Y(S) \xrightarrow{L^{-1}T} y(t)$$

EX: $\dot{X} = \begin{bmatrix} 0 & 1 \\ -2 & -3 \end{bmatrix} X + \begin{bmatrix} 0 \\ 2 \end{bmatrix} u(t)$

$y(t) = \begin{bmatrix} 0 & 1 \end{bmatrix} X(t)$ & $X(0) = \begin{bmatrix} 0 \\ 1 \end{bmatrix}$

Find T.F. & $y(t)$ for unit-Step response

Solution:-

$$T.F. = C(SI - A)^{-1} B$$

$$*(SI - A) = \begin{pmatrix} S & 0 \\ 0 & S \end{pmatrix} - \begin{pmatrix} 0 & 1 \\ -2 & -3 \end{pmatrix} = \begin{pmatrix} S & -1 \\ 2 & S+3 \end{pmatrix}$$

$$*(SI - A)^{-1} = \frac{1}{S(S+3)} \begin{pmatrix} S+3 & 1 \\ -2 & S \end{pmatrix}$$

$$* \; (SI - A)^{-1} = \frac{1}{s^2+3s+2} \begin{pmatrix} s+3 & 1 \\ -2 & s \end{pmatrix}$$

$$T.F. = C\,(SI-A)^{-1}\,B$$

$$= \begin{bmatrix} 0 & 1 \end{bmatrix} * \frac{1}{s^2+3s+2} \begin{pmatrix} s+3 & 1 \\ -2 & s \end{pmatrix} \begin{pmatrix} 0 \\ 2 \end{pmatrix}$$

$$= \frac{1}{s^2+3s+2} \begin{pmatrix} 0 & 1 \end{pmatrix} \begin{pmatrix} s+3 & 1 \\ -2 & s \end{pmatrix} \begin{pmatrix} 0 \\ 2 \end{pmatrix}$$

$$= \frac{1}{s^2+3s+2} \begin{pmatrix} 0 & 1 \end{pmatrix} \begin{pmatrix} 2 \\ 2s \end{pmatrix}$$

$$= \frac{2s}{s^2+3s+2}$$

Ch. eqn : $|SI - A| = 0$ محسوب سابقا

$$s^2+3s+2 = 0$$

$$X(s) = \phi(s)\,X(0) + \phi(s)\,B\,u(s)$$

$$\phi(s) = (SI-A)^{-1} = \frac{1}{s^2+3s+2} \begin{pmatrix} s+3 & 1 \\ -2 & s \end{pmatrix}$$

$$X(s) = \frac{1}{(s^2+3s+2)} \begin{pmatrix} s+3 & 1 \\ -2 & s \end{pmatrix} \begin{pmatrix} 0 \\ 1 \end{pmatrix}$$

$u(t) = 1$
$U(s) = 1/s$

$$+ \frac{1}{(s^2+3s+2)} \begin{pmatrix} s+3 & 1 \\ -2 & s \end{pmatrix} \begin{pmatrix} 0 \\ \cancel{2} \end{pmatrix} \left(1/s\right)$$

$2/s$

$$= \frac{1}{s^2+3s+2}\left[\begin{pmatrix}1\\ s\end{pmatrix}+\begin{pmatrix}2/s\\ 2\end{pmatrix}\right]$$

$$= \frac{1}{s^2+3s+2}\begin{pmatrix}1+\frac{2}{s}\\ s+2\end{pmatrix}$$

$$X(s) = \frac{1}{(s+1)(s+2)}\begin{pmatrix}\frac{s+2}{s}\\ s+2\end{pmatrix} = \begin{pmatrix}\frac{1}{s(s+1)}\\ \frac{1}{s+1}\end{pmatrix}$$

$$Y(s) = C\,X(s)$$

$$= \begin{pmatrix}0 & 1\end{pmatrix}\begin{pmatrix}\frac{1}{s(s+1)}\\ \frac{1}{s+1}\end{pmatrix}$$

$$Y(s) = \frac{1}{s+1} \Rightarrow L^{-1}T \quad y(t) = e^{-t}$$

unit-Step Response

$\boxed{4}$ Controllability

* The system is completely controllable if the system states can be changed by changing the system i/p

* Another definition :-

The ability of control i/P signal of a system to move any initial state to another final states during finite intervals of time

$$x(t_0) \longrightarrow x(t_1)$$

Controllability Matrix (M_c)

$$M_c = \begin{pmatrix} B & AB & A^2B & \cdots & A^{n-1}B \end{pmatrix}$$

if $|M_c| \neq 0$, the system is controllable.

* 2nd order $\Rightarrow$ $M_c = \begin{pmatrix} B & AB \end{pmatrix}$

* 3rd order $\Longrightarrow$ $M_c = \begin{pmatrix} B & AB & A^2B \end{pmatrix}$ $\quad$ n-1

$\boxed{5}$ observability

* In some cases the states connot be measured for the following reasons

1- The location for phisycal states :-

2- The measuring instruments are not valid.

in this case, an estimation for these states is required

* If the internal states of a system could be estimated (calculated) from the observation of o/p response, then the system is called observable.

observability matrix (M_o)

$$M_o = \begin{pmatrix} C \\ CA \\ CA^2 \\ \vdots \\ CA^{n-1} \end{pmatrix}$$

$|M_o| \neq 0 \Rightarrow$ observable

$M_o = \begin{pmatrix} C \\ CA \end{pmatrix} \rightarrow$ 2nd order

$M_o = \begin{pmatrix} C \\ CA \\ CA^2 \end{pmatrix} \rightarrow$ 3rd order

Ex: $A = \begin{pmatrix} 1 & 1 & 0 \\ 0 & 1 & -1 \\ 0 & 1 & 1 \end{pmatrix}$, $B = \begin{pmatrix} 0 \\ 1 \\ 0 \end{pmatrix}$

$$C = \begin{pmatrix} 1 & 0 & 1 \end{pmatrix}$$

$$M_C = \begin{pmatrix} B & AB & A^2B \end{pmatrix}$$

$AB = \begin{pmatrix} 1 \\ 1 \\ 1 \end{pmatrix}$, $A^2B = A.AB = \begin{pmatrix} 1 & 1 & 0 \\ 0 & 1 & -1 \\ 0 & 1 & 1 \end{pmatrix}\begin{pmatrix} 1 \\ 1 \\ 1 \end{pmatrix}$

$$= \begin{pmatrix} 2 \\ 0 \\ 2 \end{pmatrix}$$

$$M_C = \begin{pmatrix} +0 & 1 & 2 \\ -1 & 1 & 0 \\ +0 & 1 & 2 \end{pmatrix} \Rightarrow |M_C| = \begin{vmatrix} 1 & 2 \\ 1 & 2 \end{vmatrix} = 0$$

the system is not controllable

$M_o = \begin{pmatrix} C \\ CA \\ CA^2 \end{pmatrix}$; $CA = \begin{pmatrix} 1 & 0 & 1 \end{pmatrix}\begin{pmatrix} 1 & 1 & 0 \\ 0 & 1 & -1 \\ 0 & 1 & 1 \end{pmatrix} = \begin{pmatrix} 1 & 2 & 1 \end{pmatrix}$

$$CA^2 = CA.A = \begin{pmatrix} 1 & 2 & 1 \end{pmatrix}\begin{pmatrix} 1 & 1 & 0 \\ 0 & 1 & -1 \\ 0 & 1 & 1 \end{pmatrix}$$

$$= \begin{pmatrix} 1 & 4 & -1 \end{pmatrix}$$

$$M_o = \begin{pmatrix} 1 & 0 & 1 \\ 1 & 2 & 1 \\ 1 & 4 & -1 \end{pmatrix} \Rightarrow |M_o| = \begin{vmatrix} 2 & 1 \\ 4 & -1 \end{vmatrix} + \begin{vmatrix} 1 & 2 \\ 1 & 4 \end{vmatrix}$$

$$= -6 + 2 = -4 \neq 0$$

the system is observable